

FIG. 1

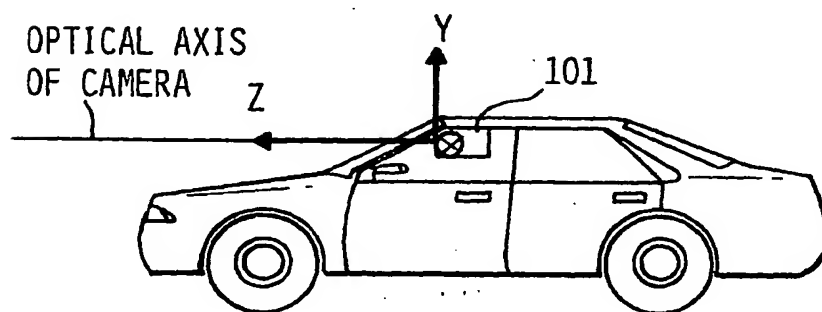


FIG 2A

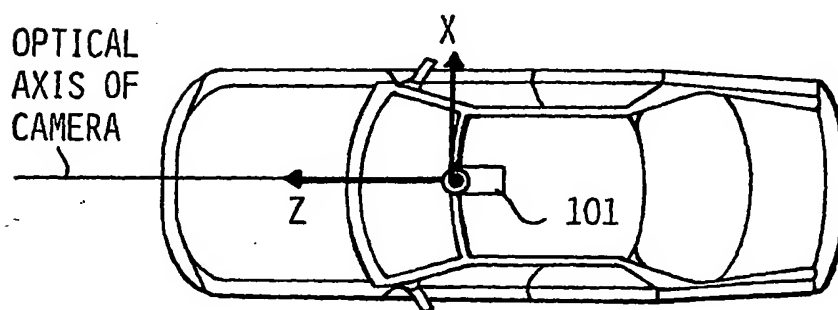


FIG 2B

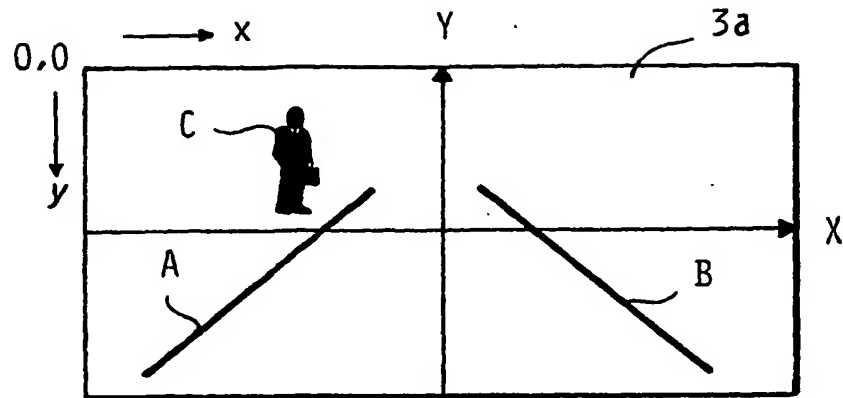


FIG. 3

CONVERSION TO
BINARY VALUE

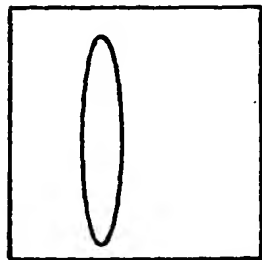


FIG. 4A

FINER LINE
FORMATION

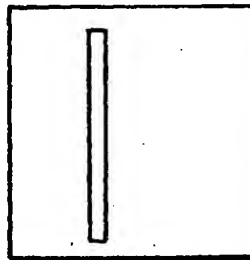


FIG. 4B

EXPANSION

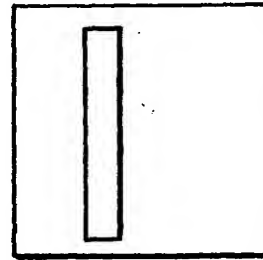


FIG. 4C

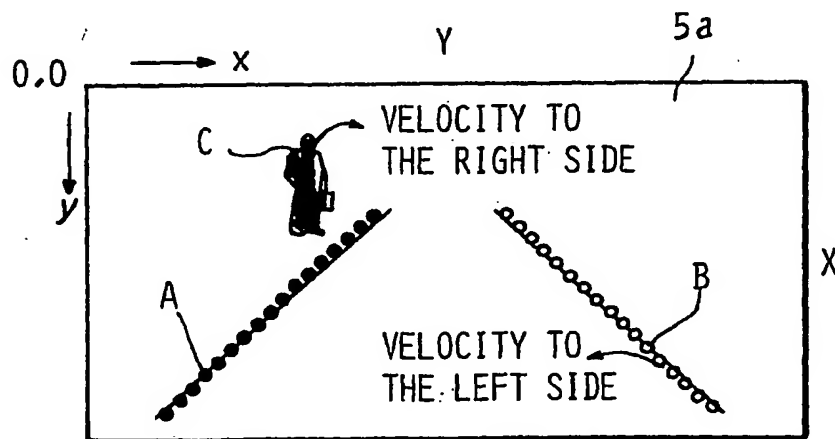


FIG. 5

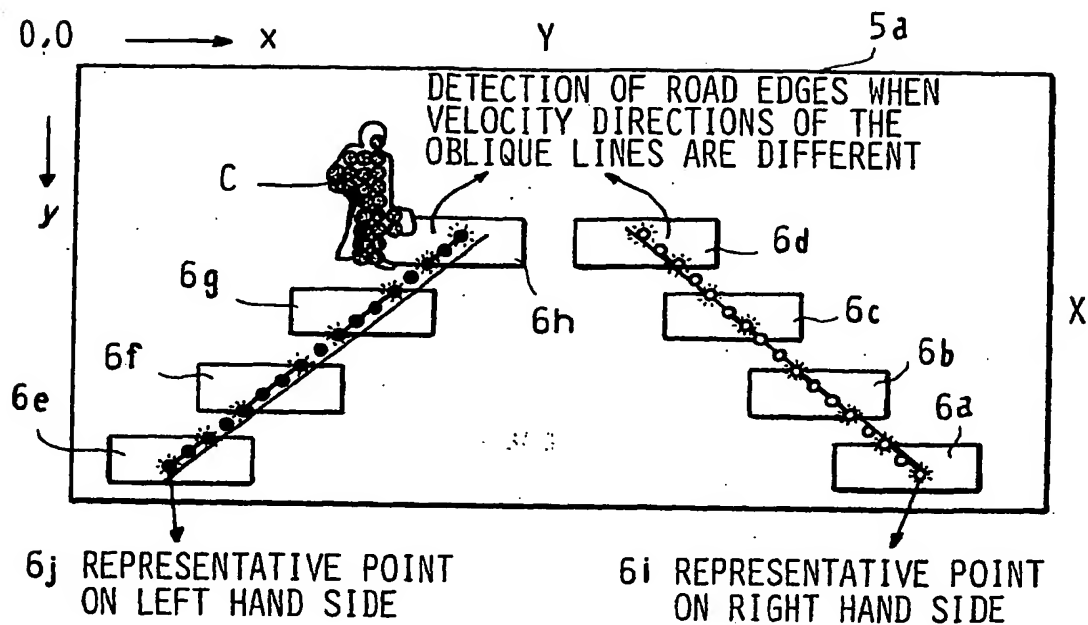


FIG. 6

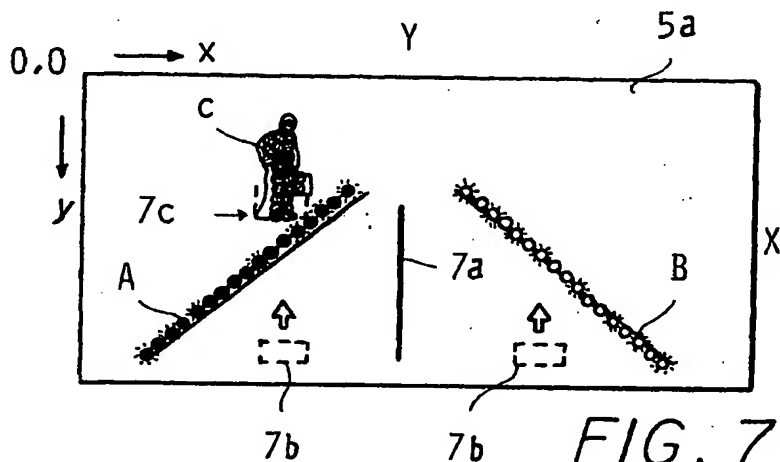


FIG. 7

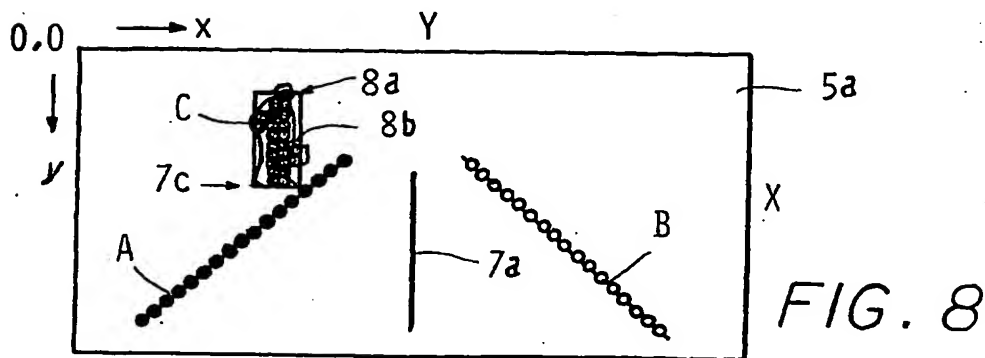


FIG. 8

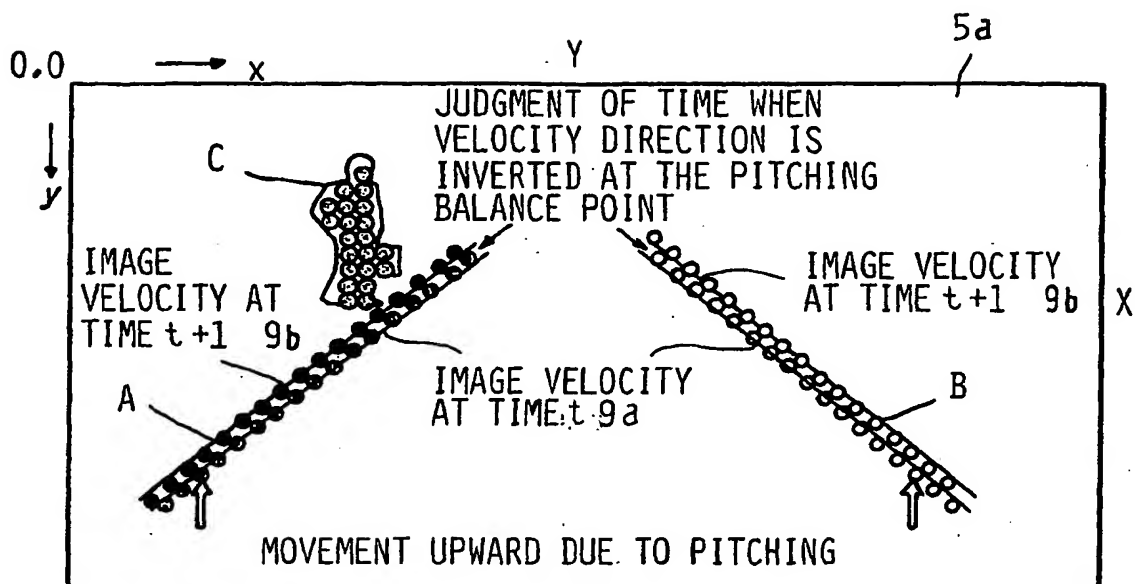


FIG. 9

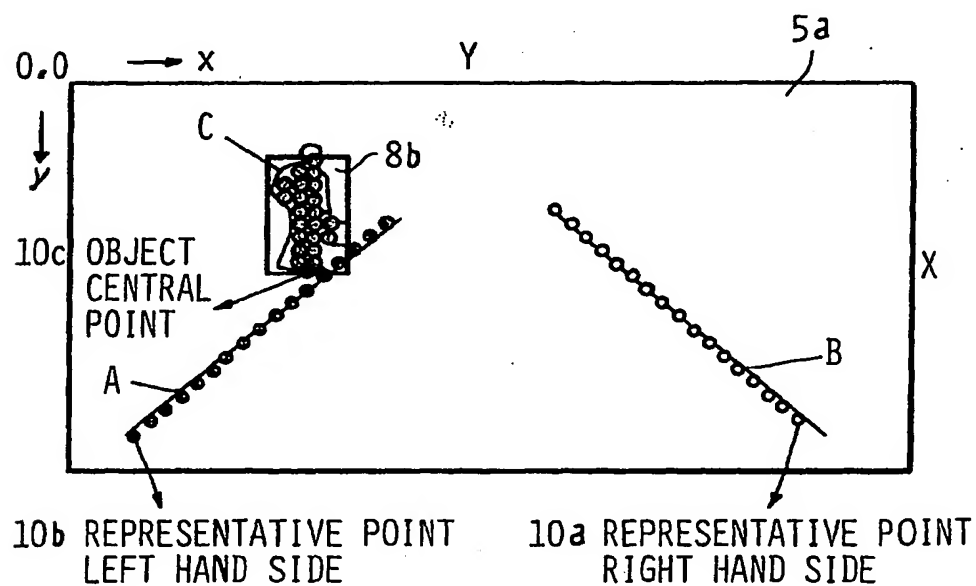


FIG. 10

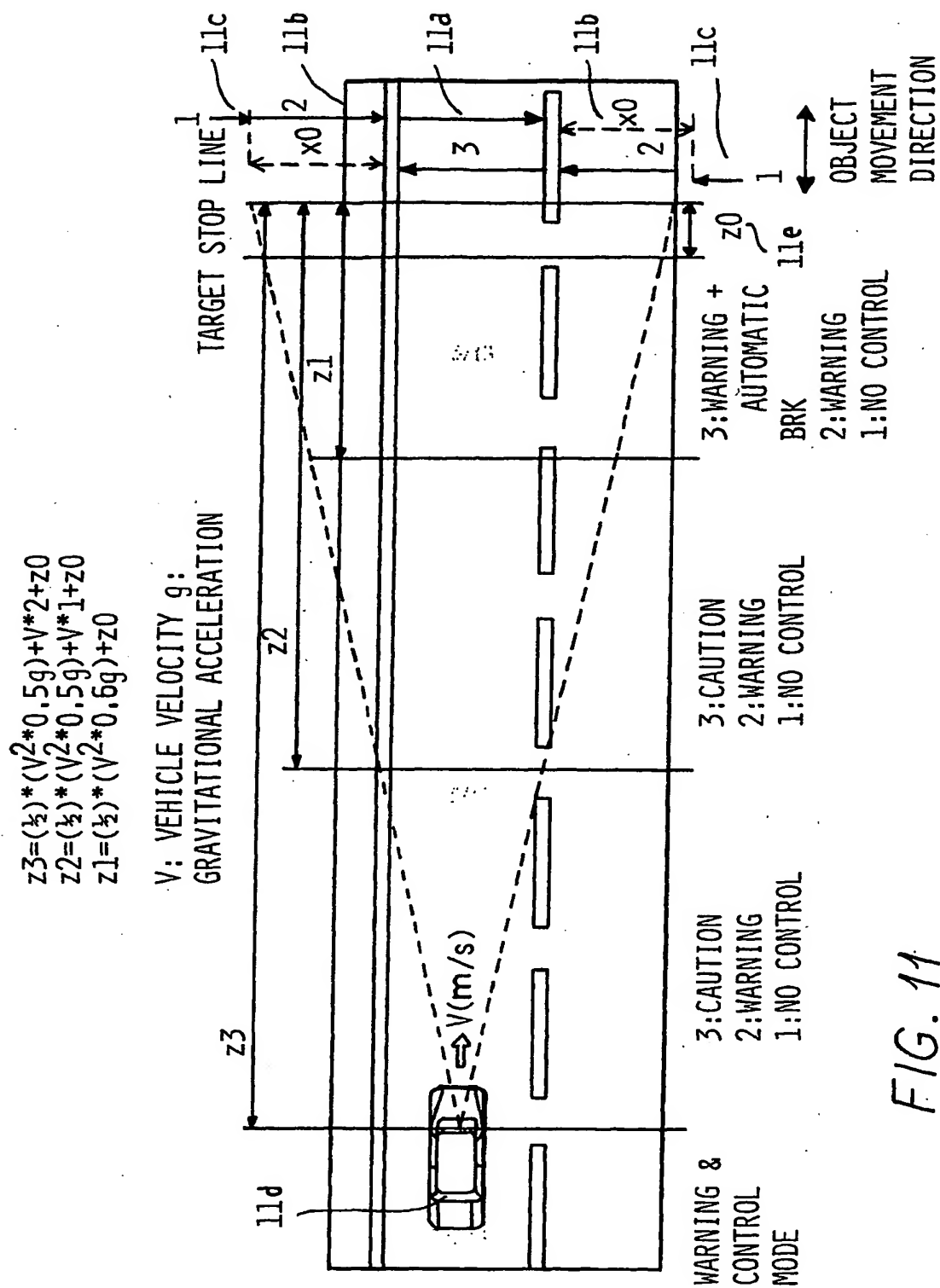


FIG. 11.

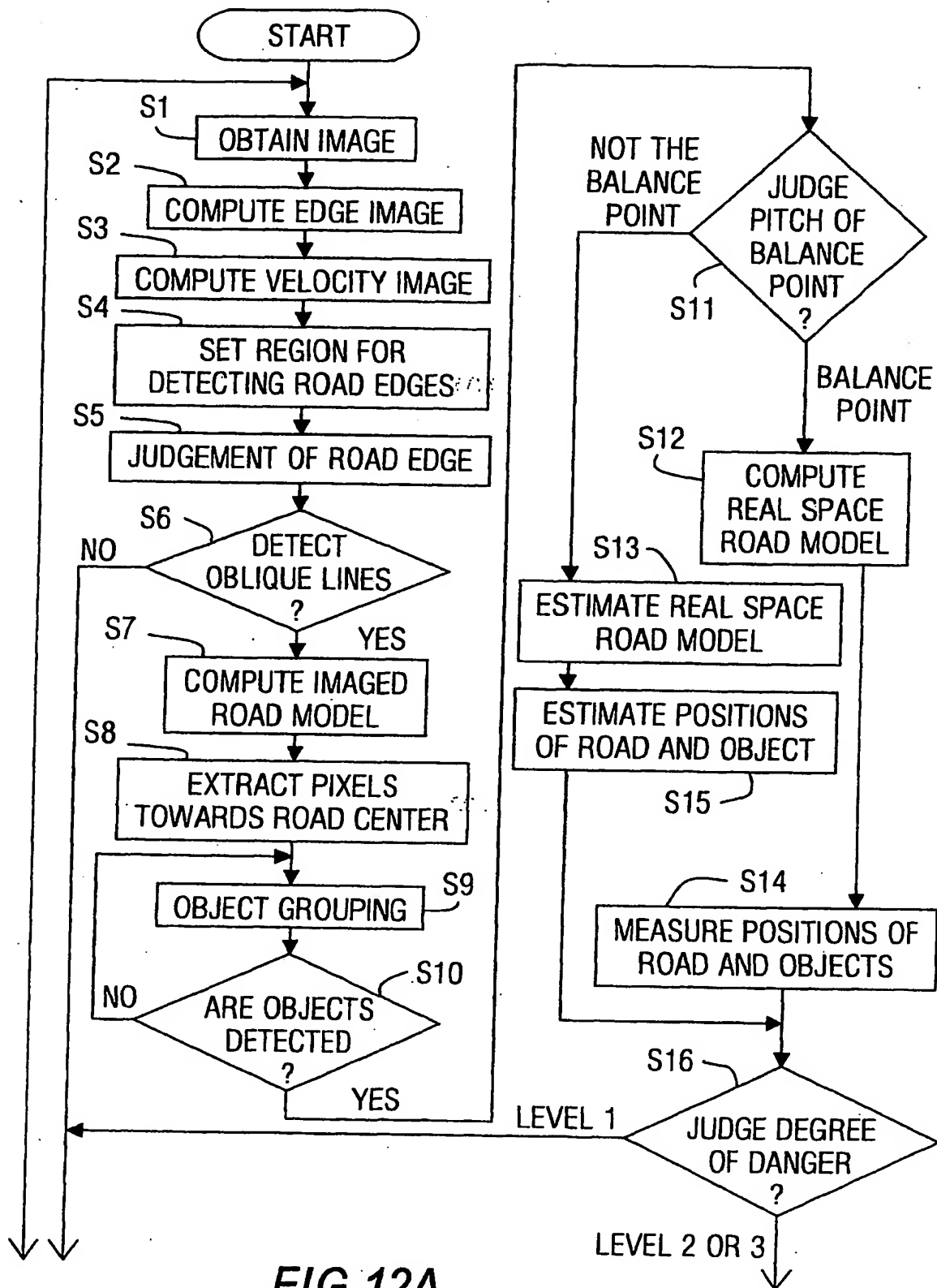
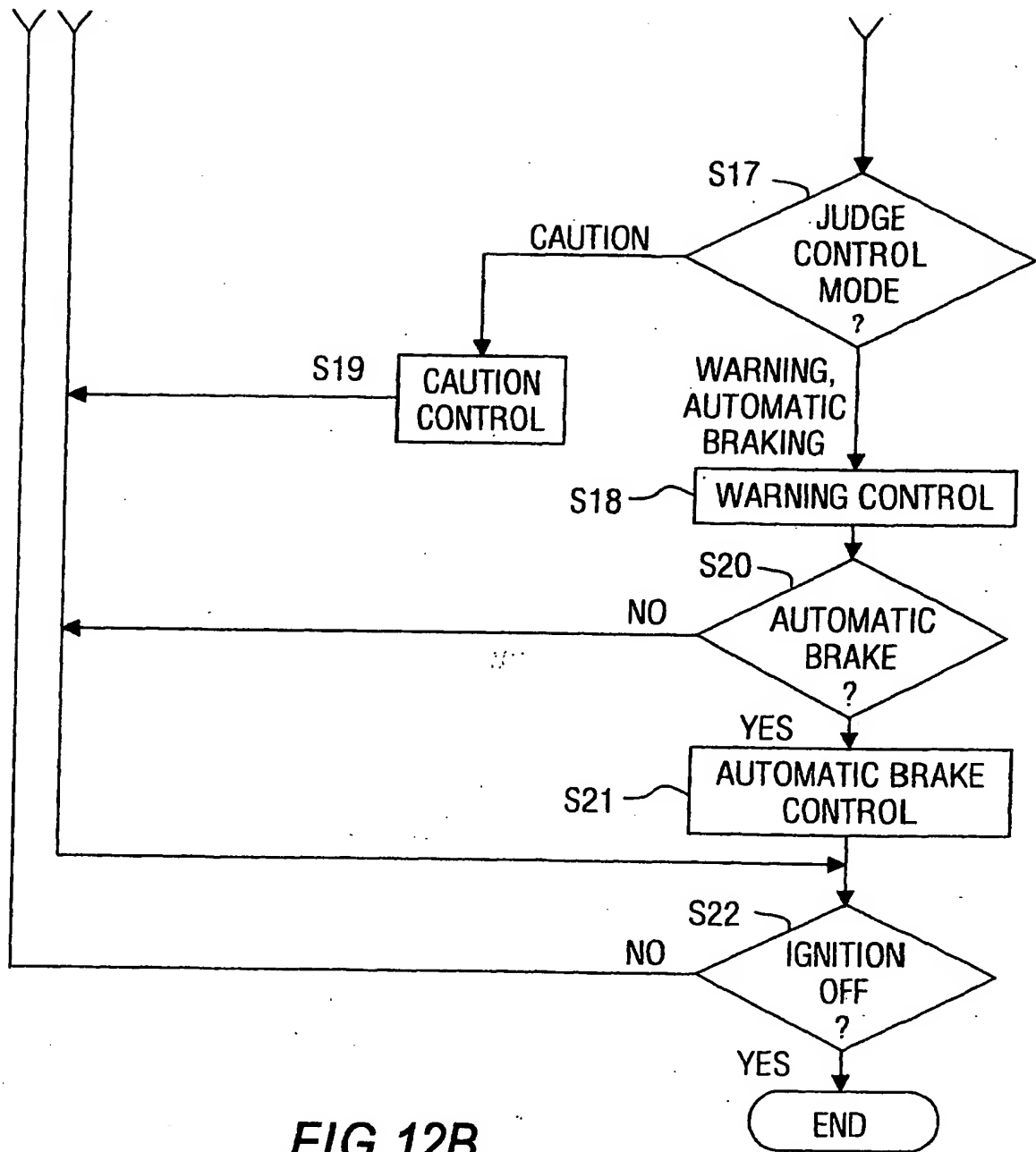


FIG 12A



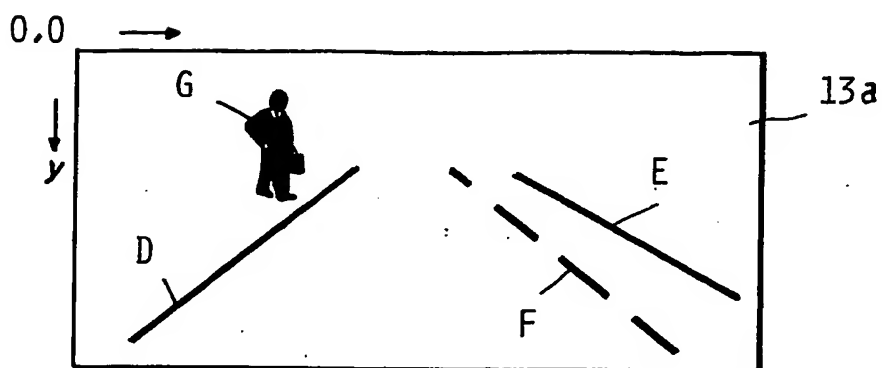


FIG. 13

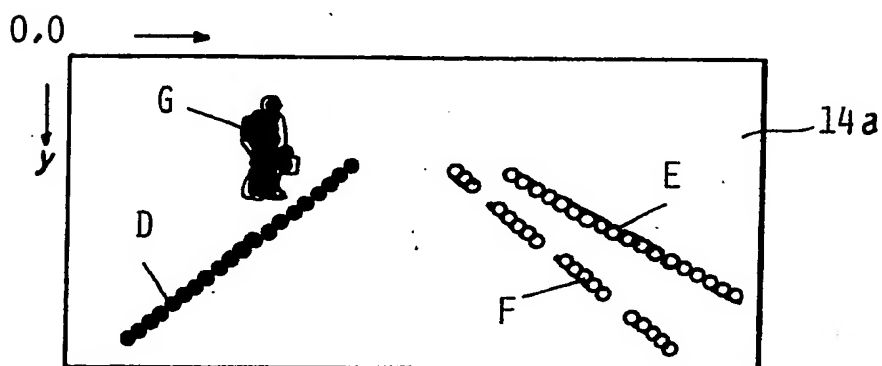


FIG. 14

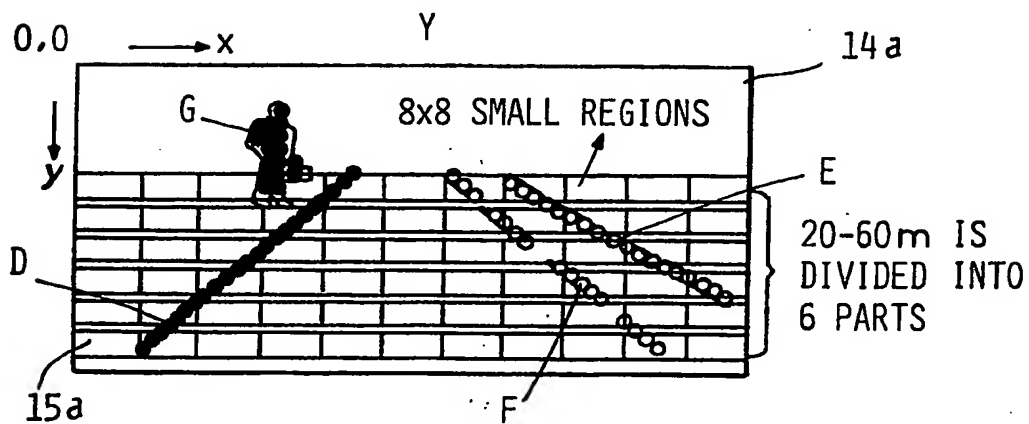
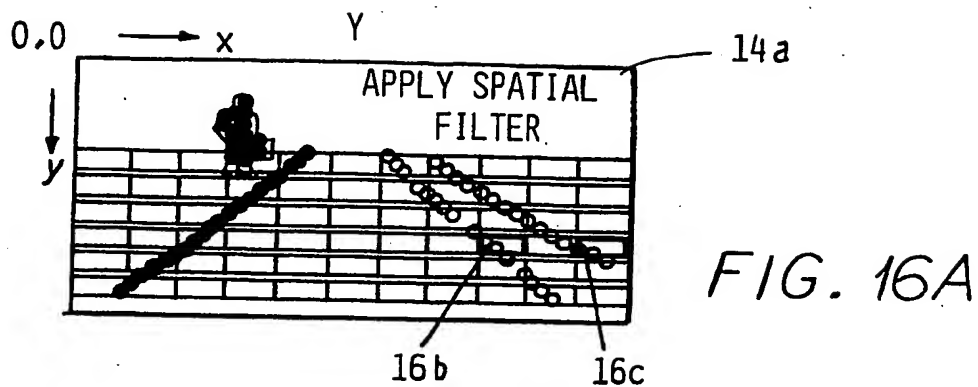


FIG. 15

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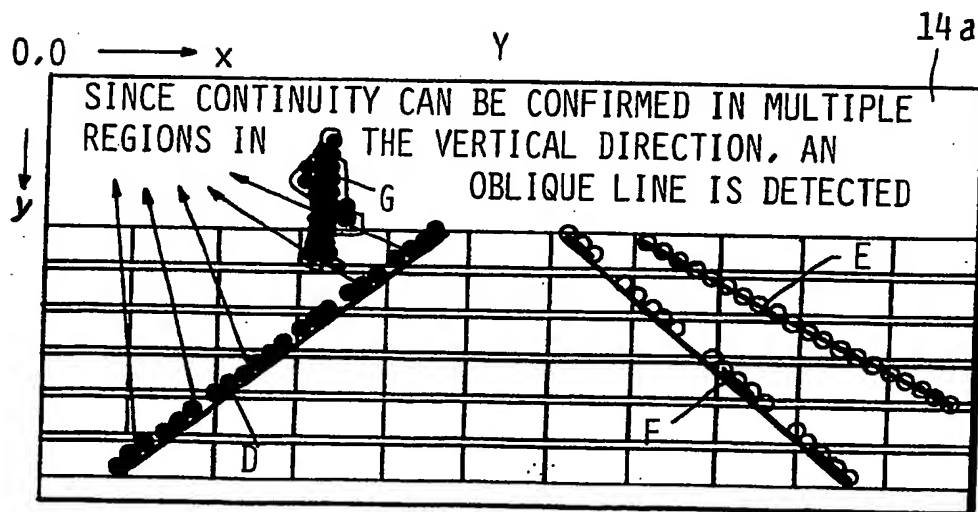
16a

1	1	0	0	0
0	0	1	0	0
0	0	0	1	1

IDENTIFIED AS A DOT CANDIDATE WHEN VELOCITY IS DETECTED ABOVE AND/OR BELOW THE DOT, IN THE OBLIQUE DIRECTION

IF A LINE SECTION FORMED BY THREE OR MORE DOT CANDIDATES SATISFIES THE SLOPE CONDITION, IT IS DETECTED AS AN OBLIQUE LINE CANDIDATE

FIG. 16B



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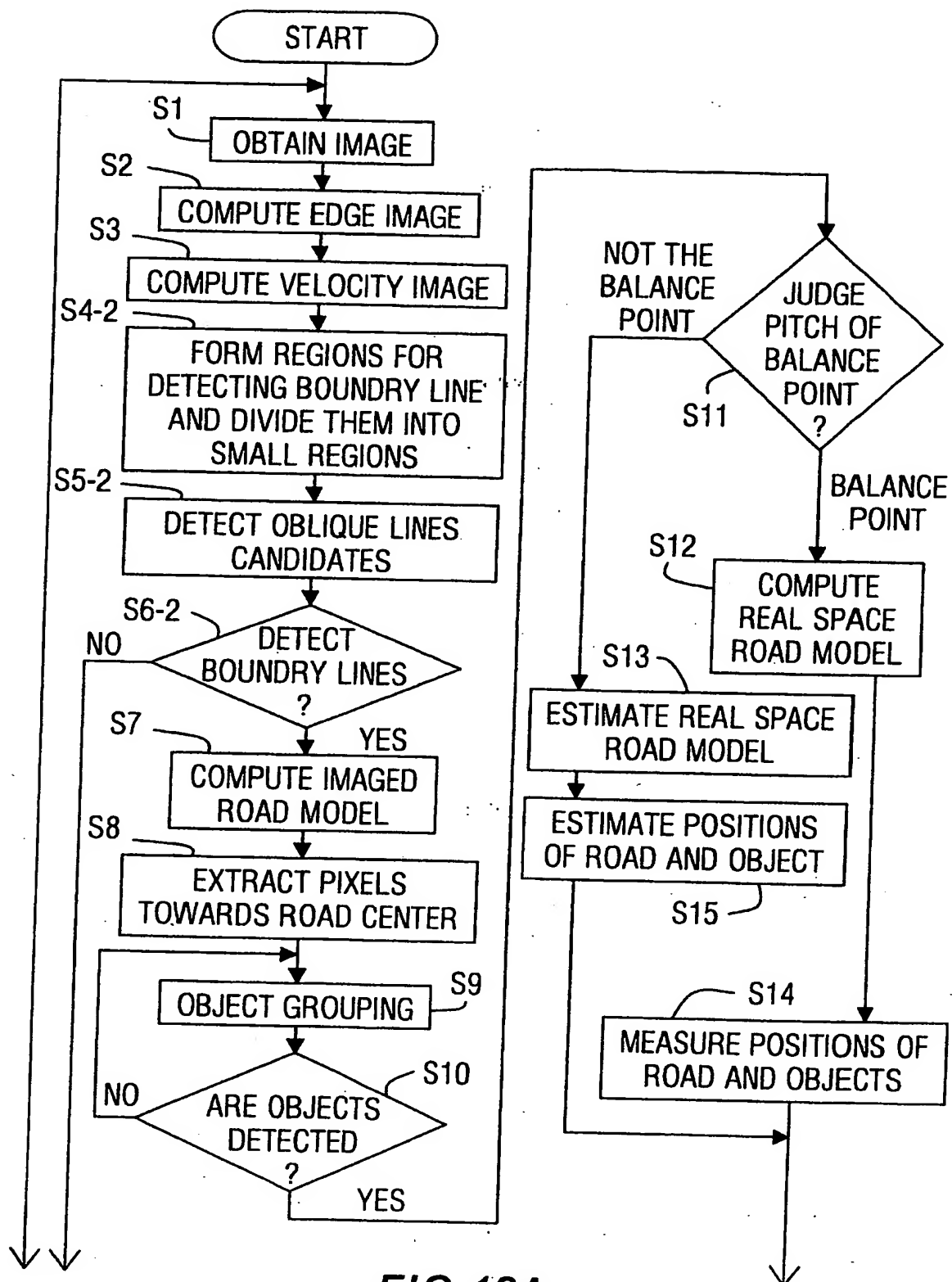


FIG 18A

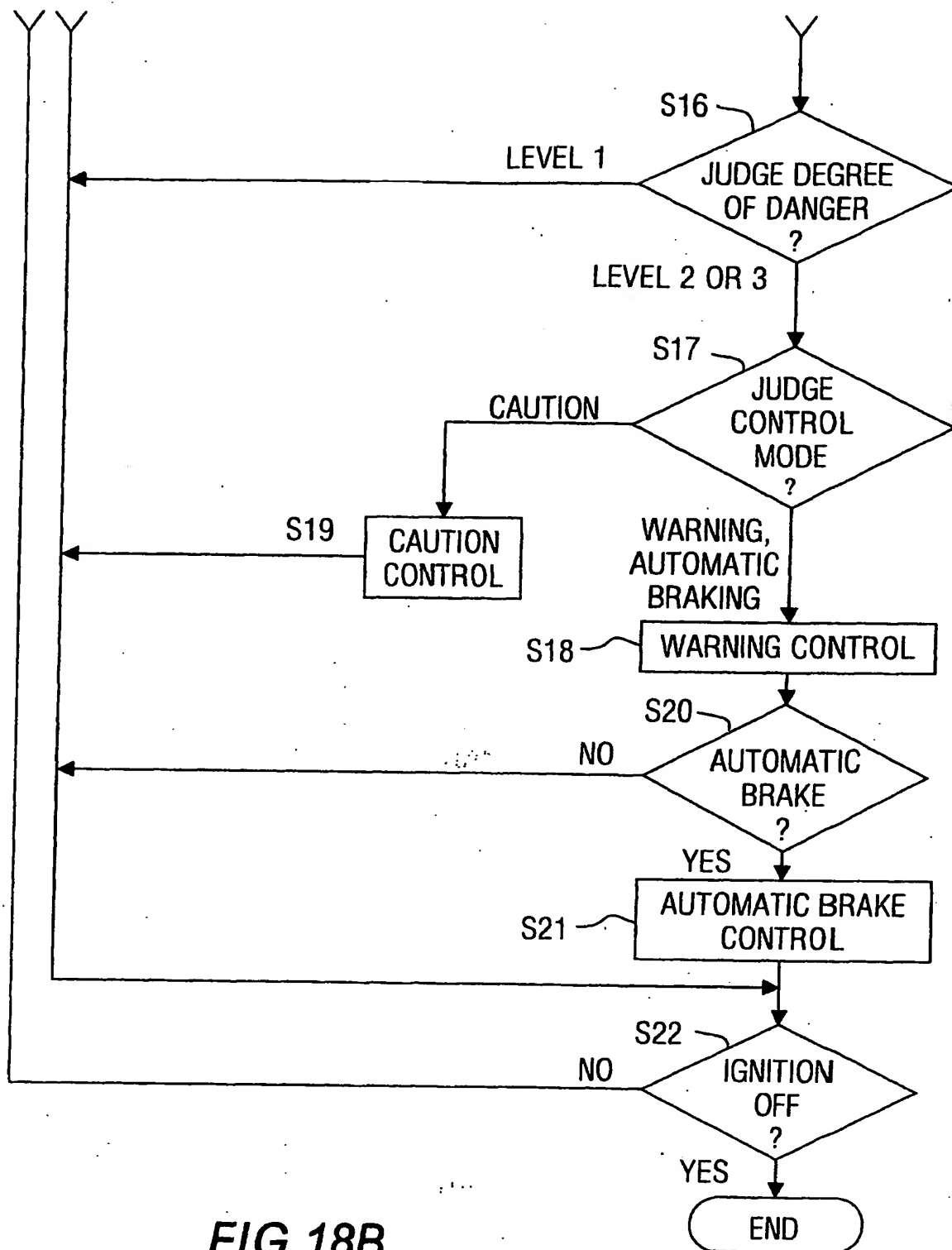


FIG 18B

FIG. 19

